

FIG. 1

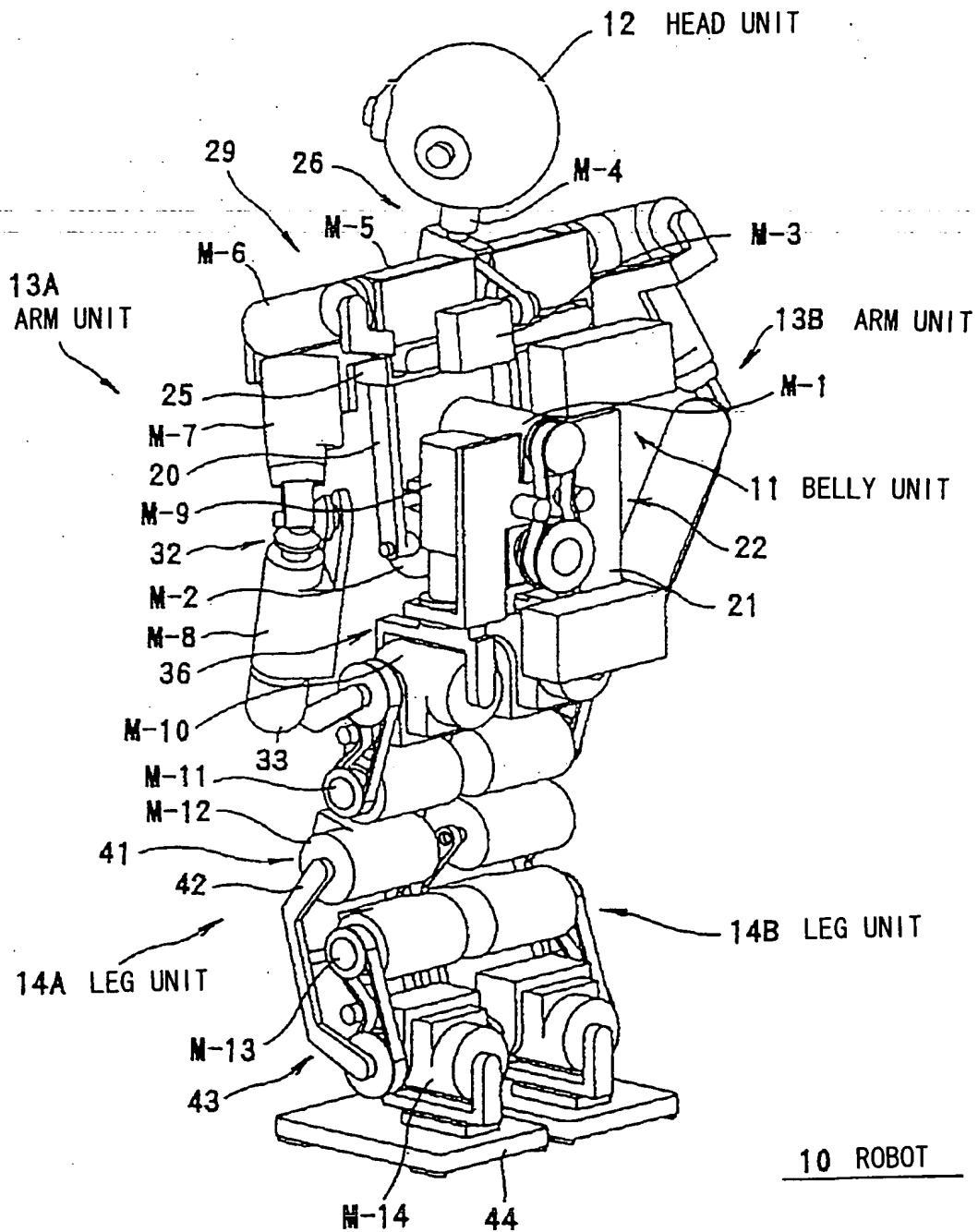


FIG. 2

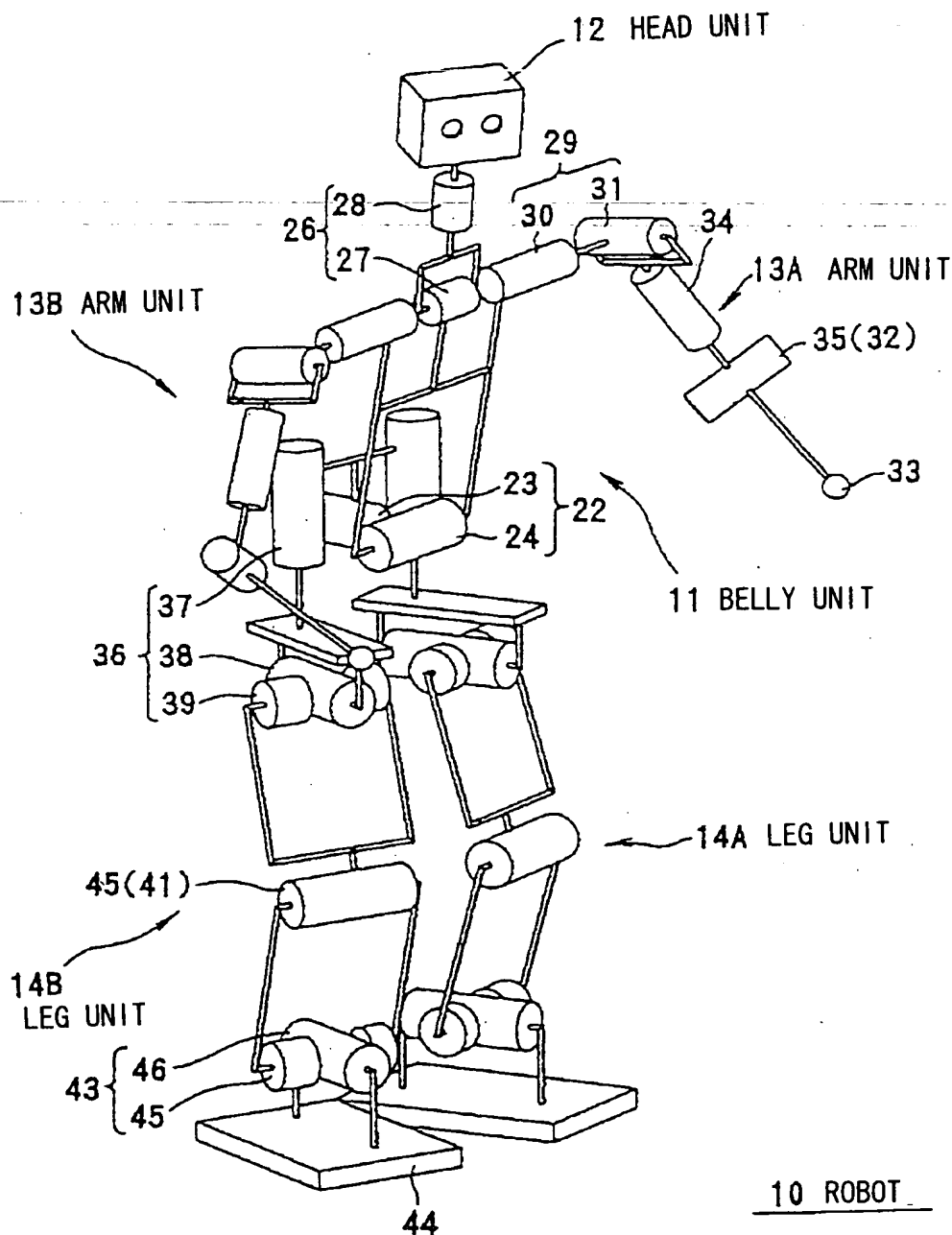


FIG. 3

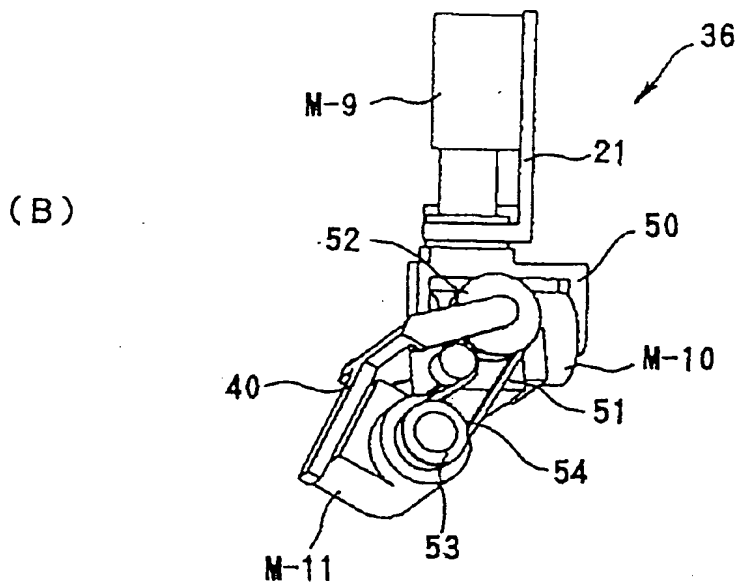
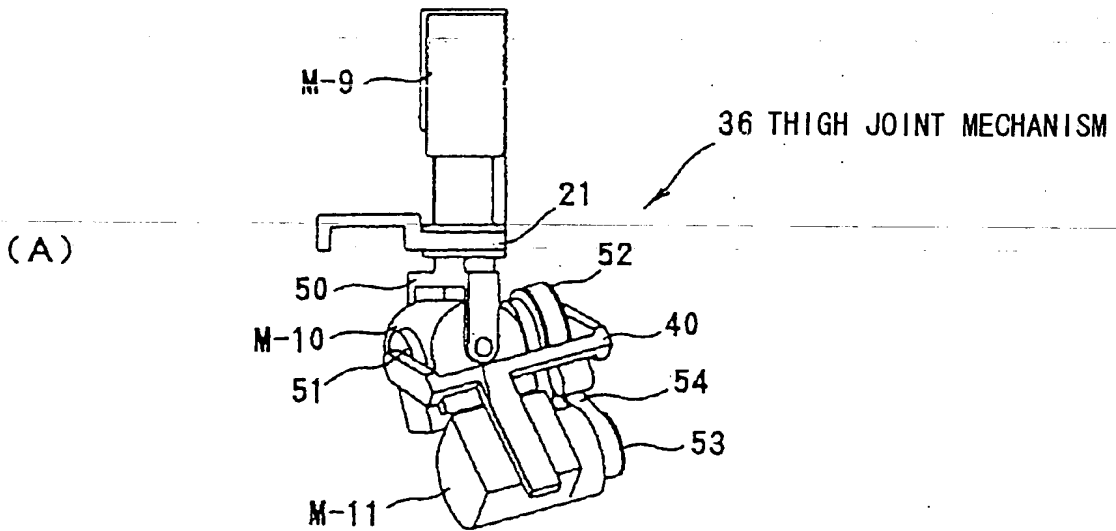


FIG. 4

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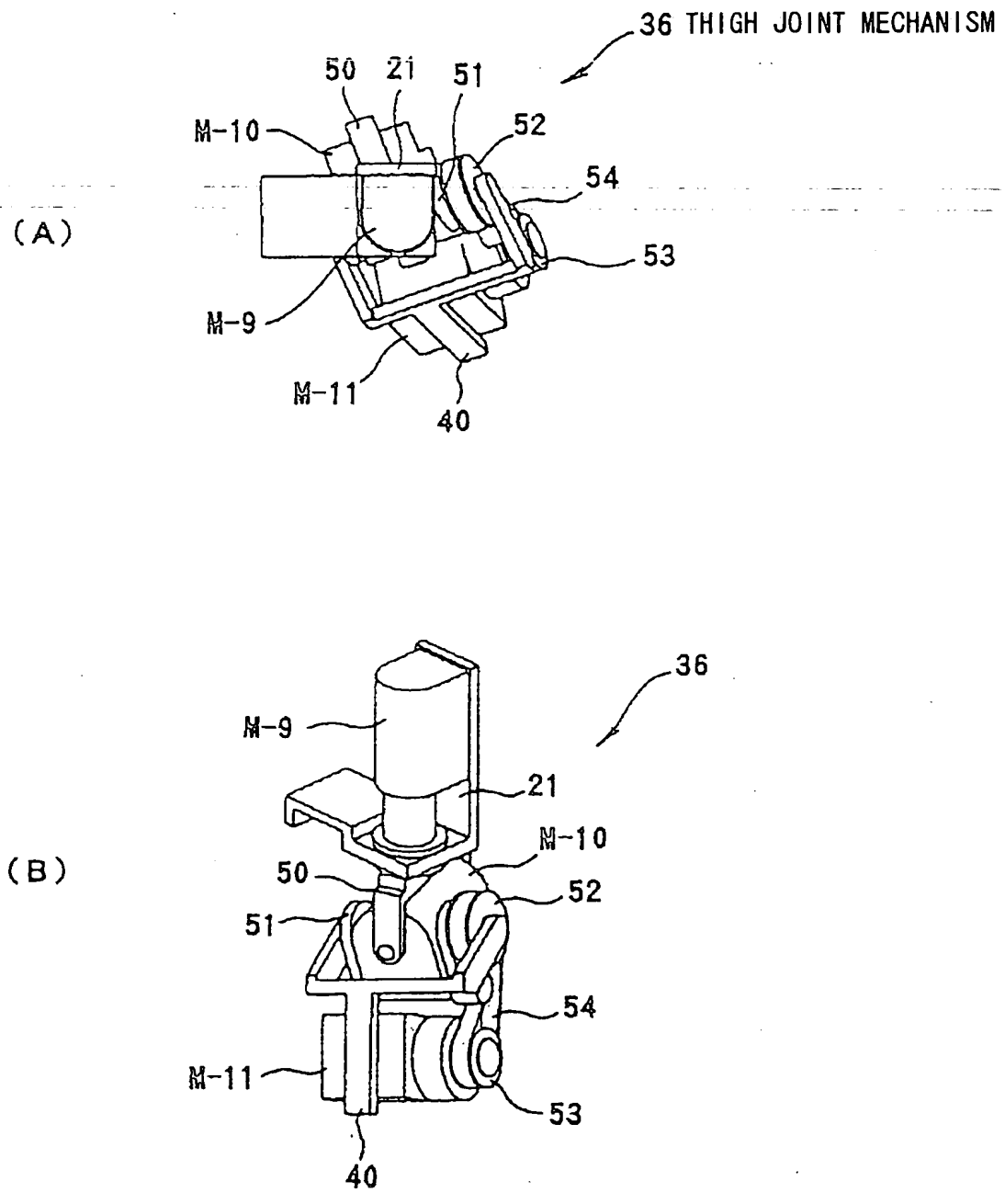
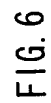


FIG. 5



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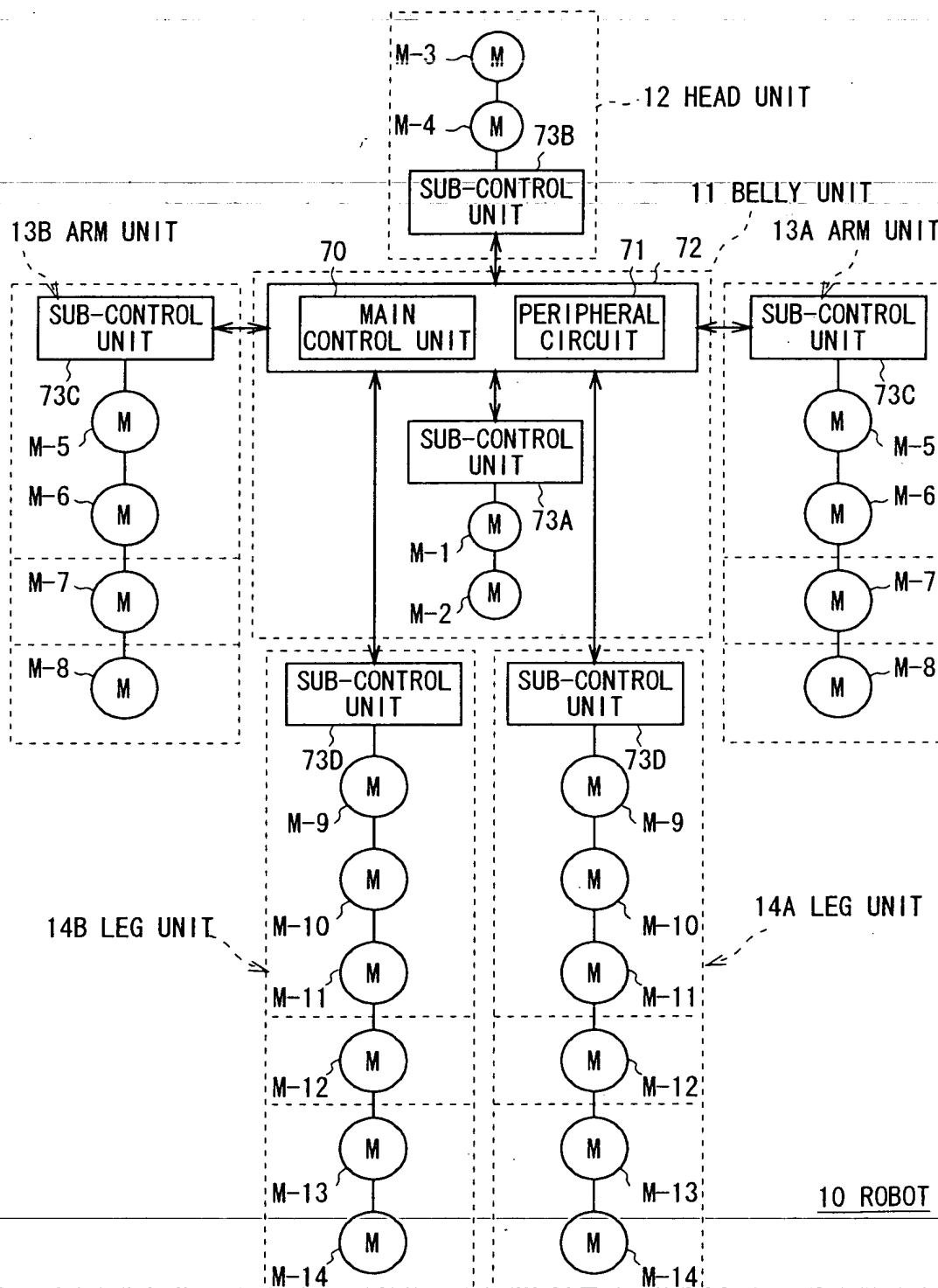


FIG. 7

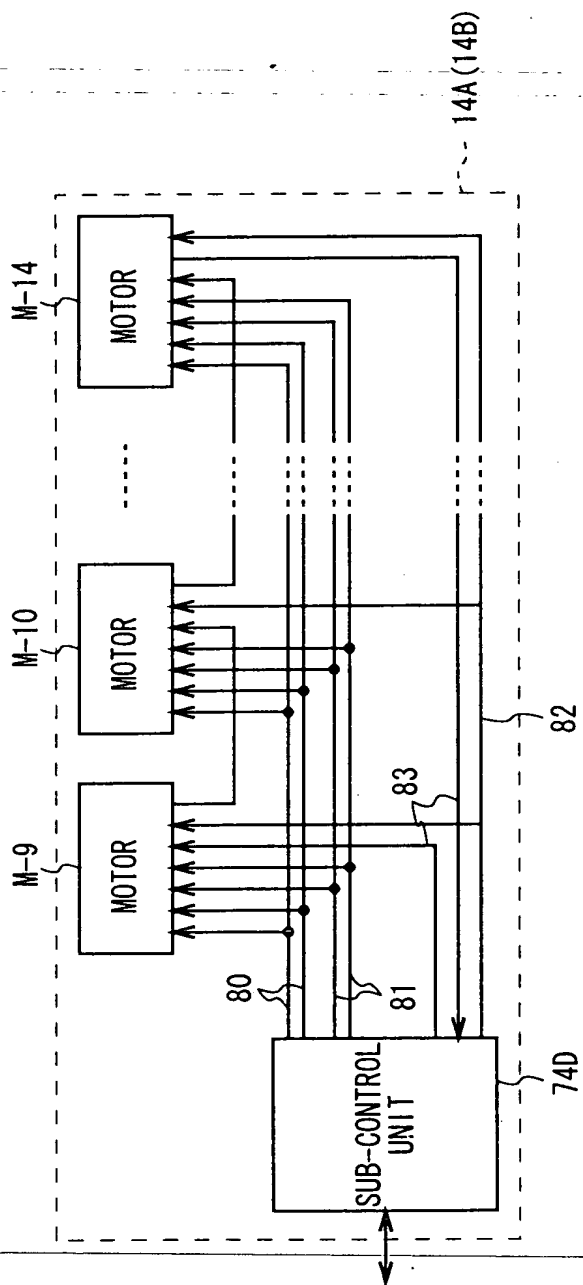


FIG. 8

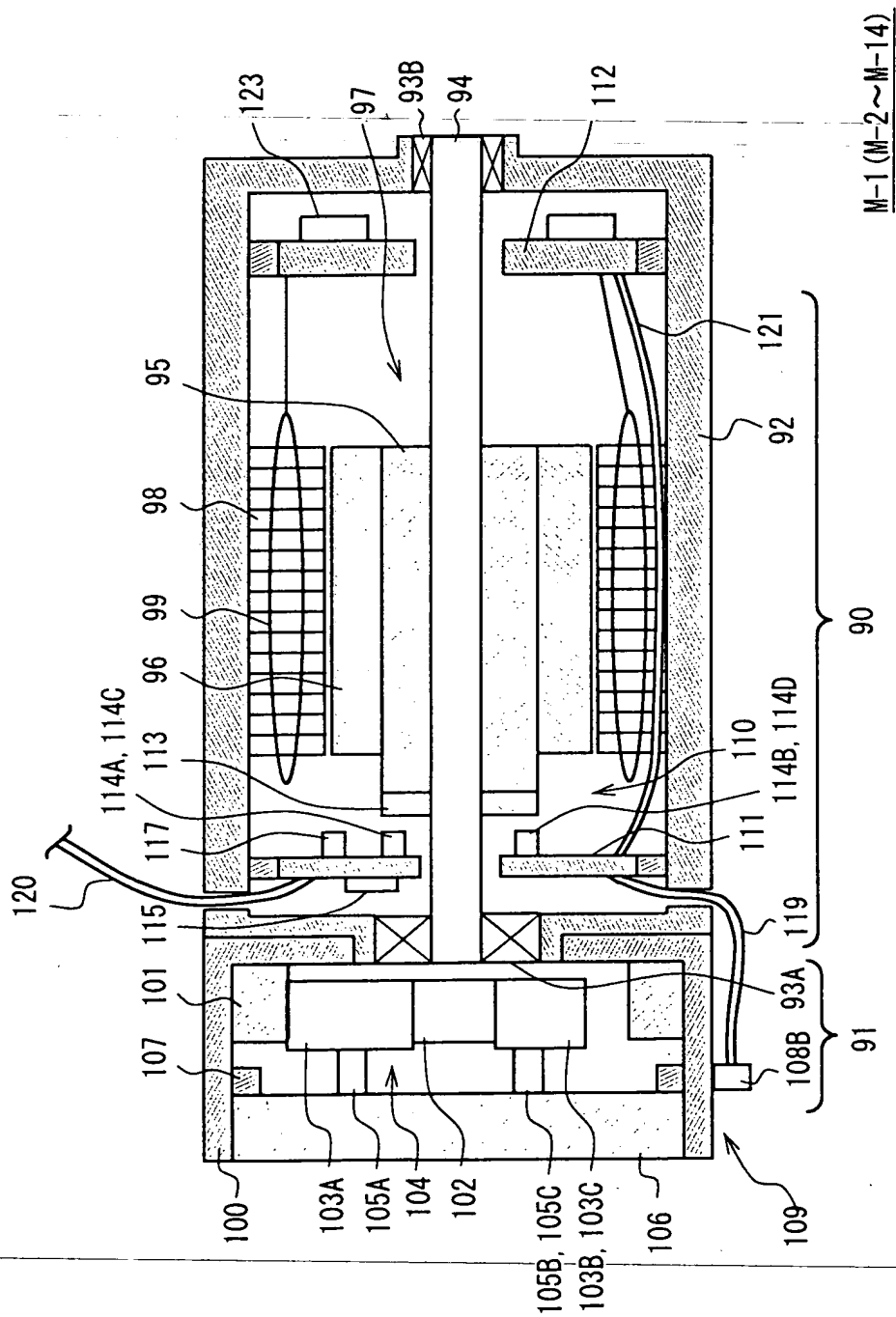


FIG. 9

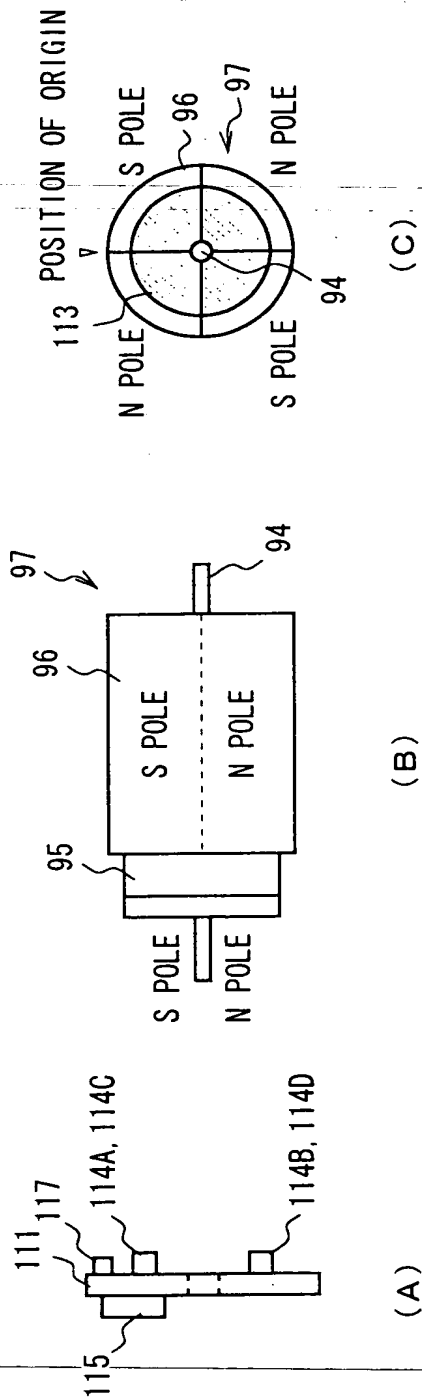


FIG. 10

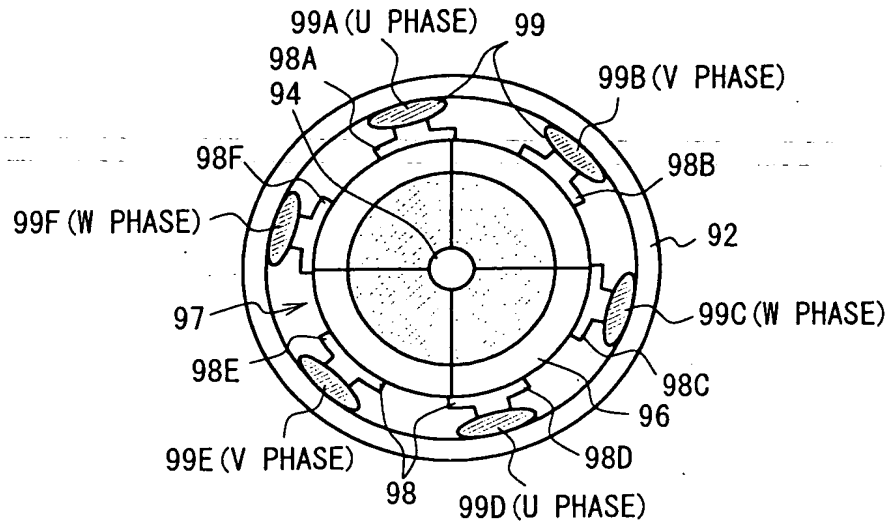


FIG. 11

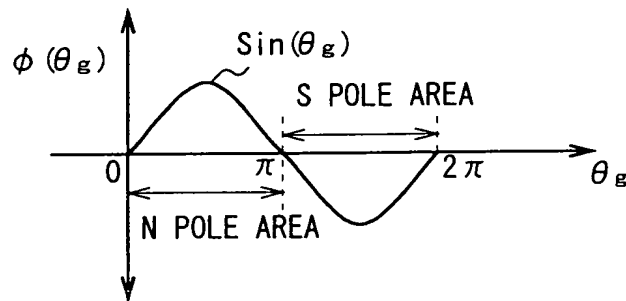


FIG. 14

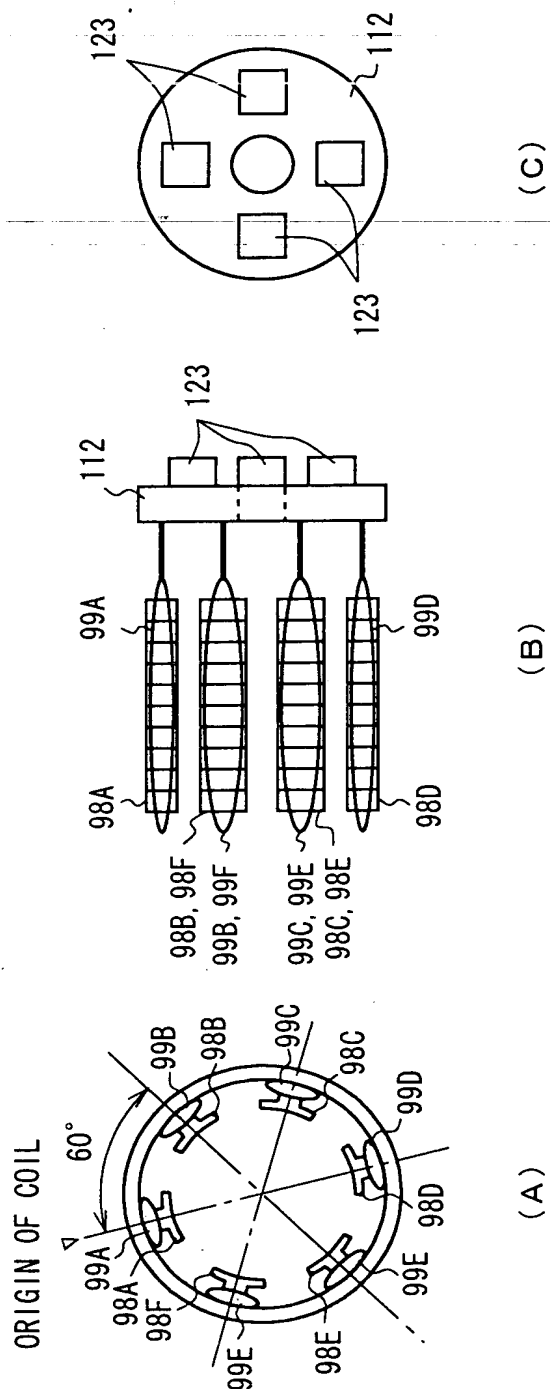


FIG. 12

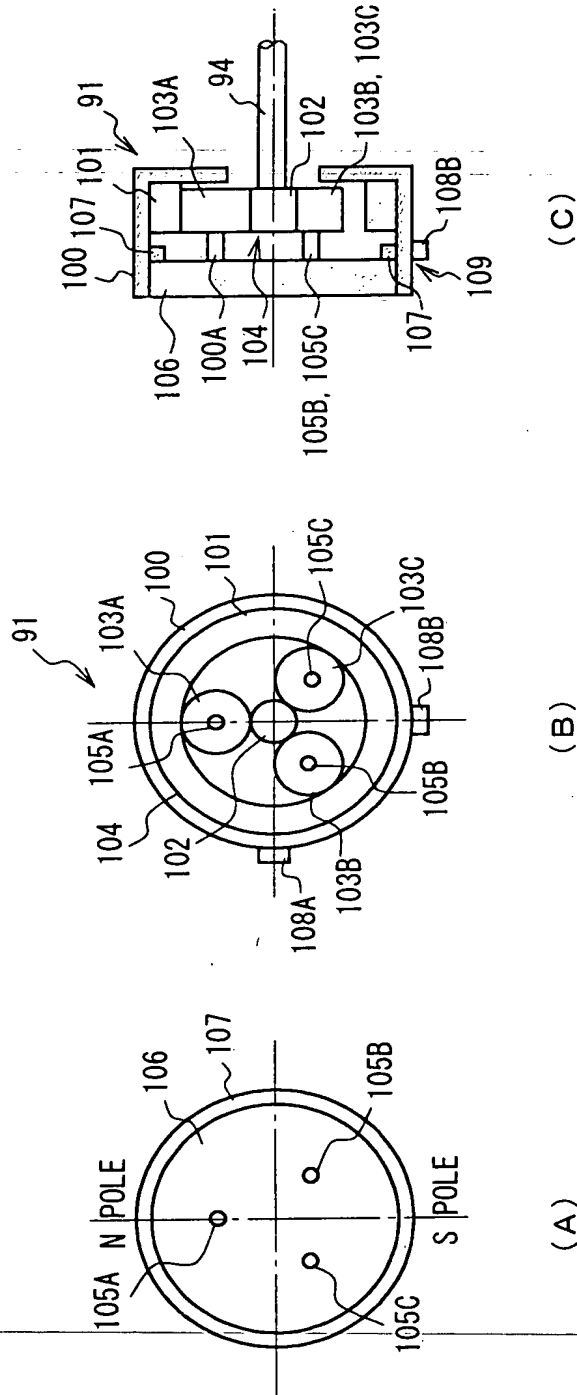
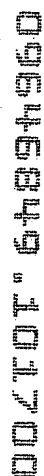


FIG. 13



(A)



FIG. 16

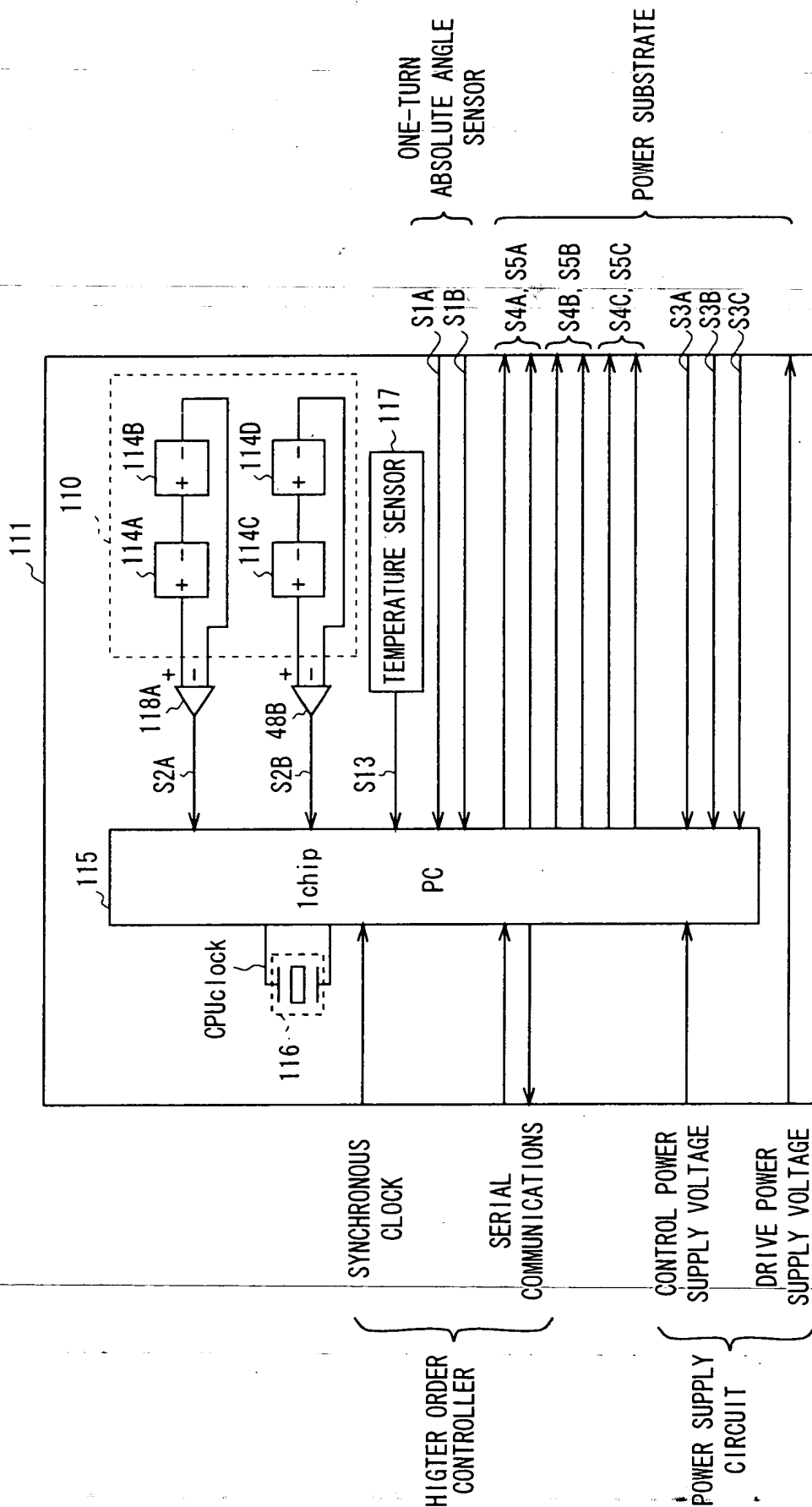
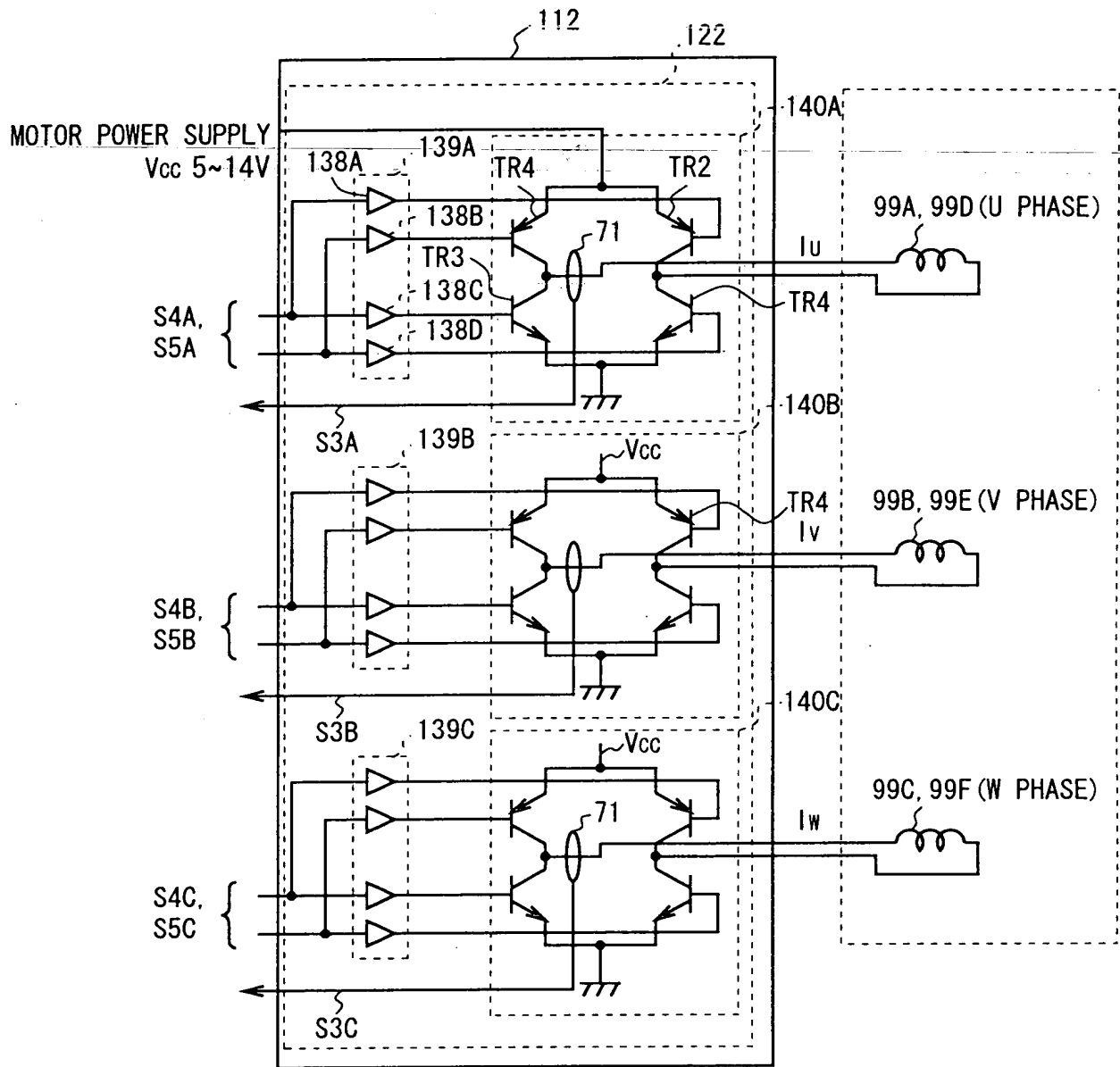
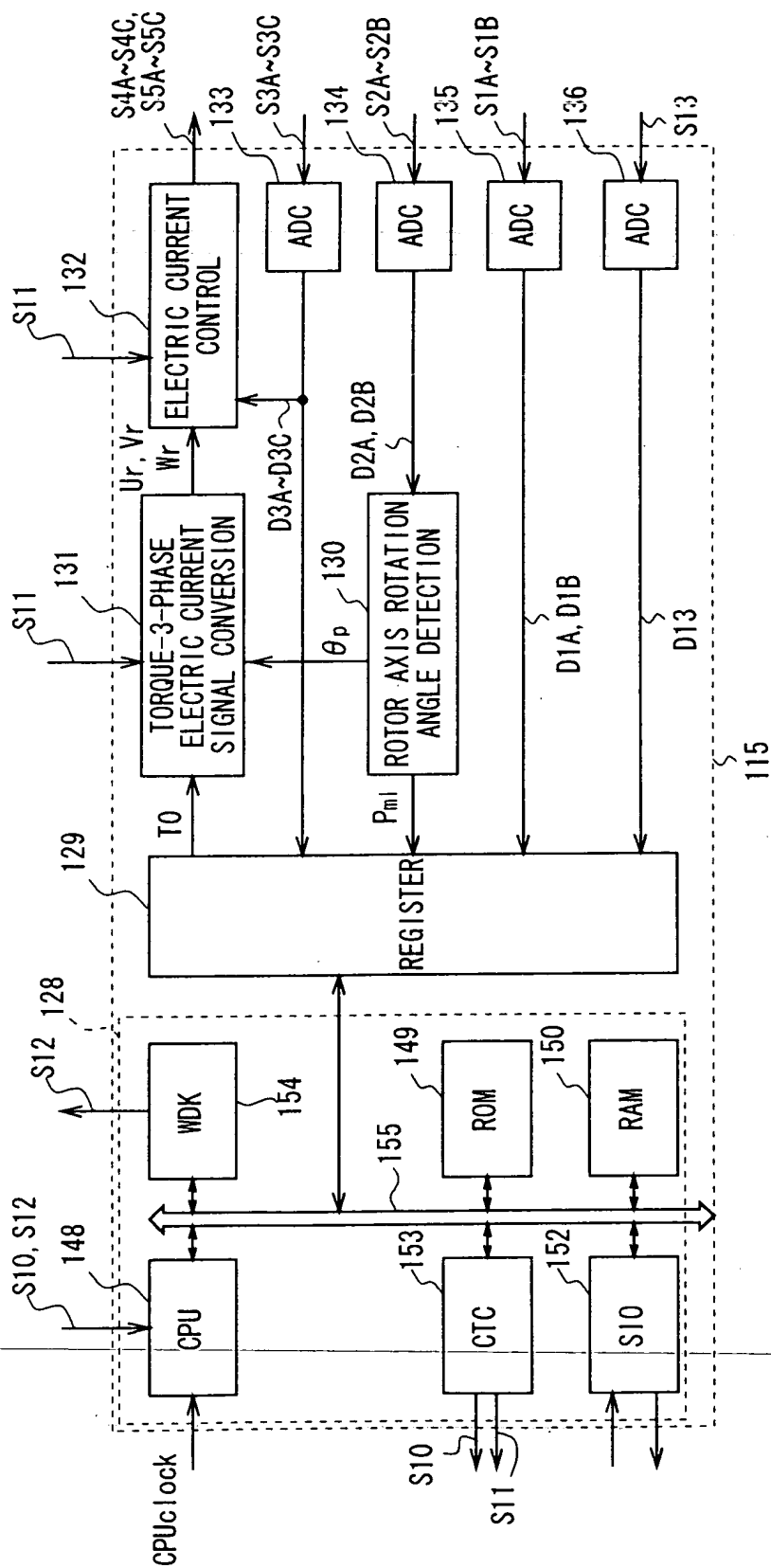
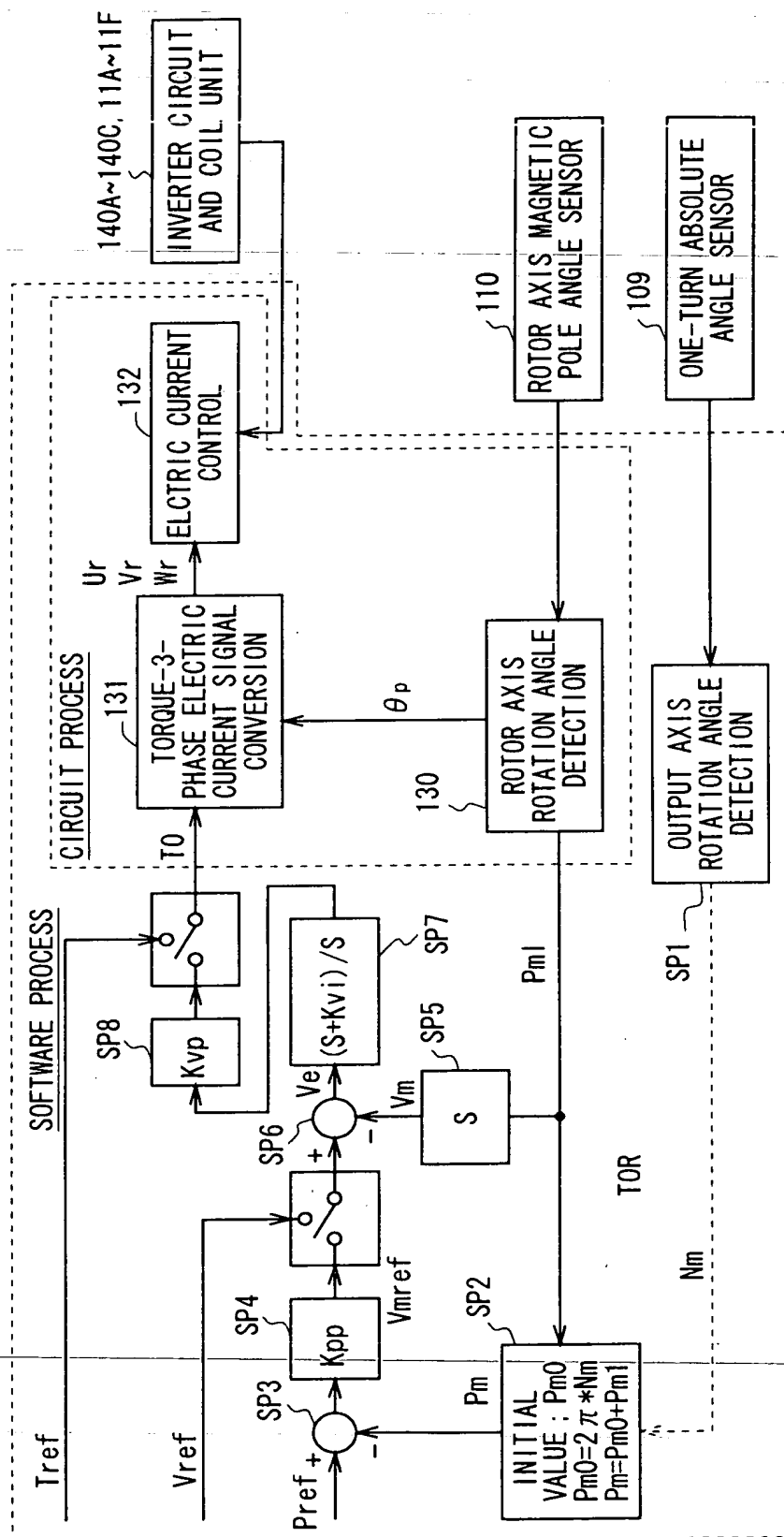


FIG. 17







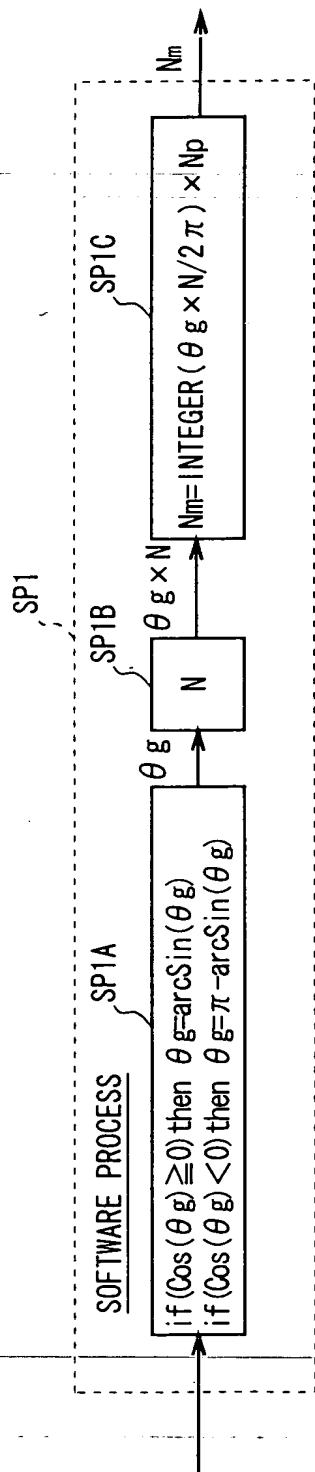


FIG. 21

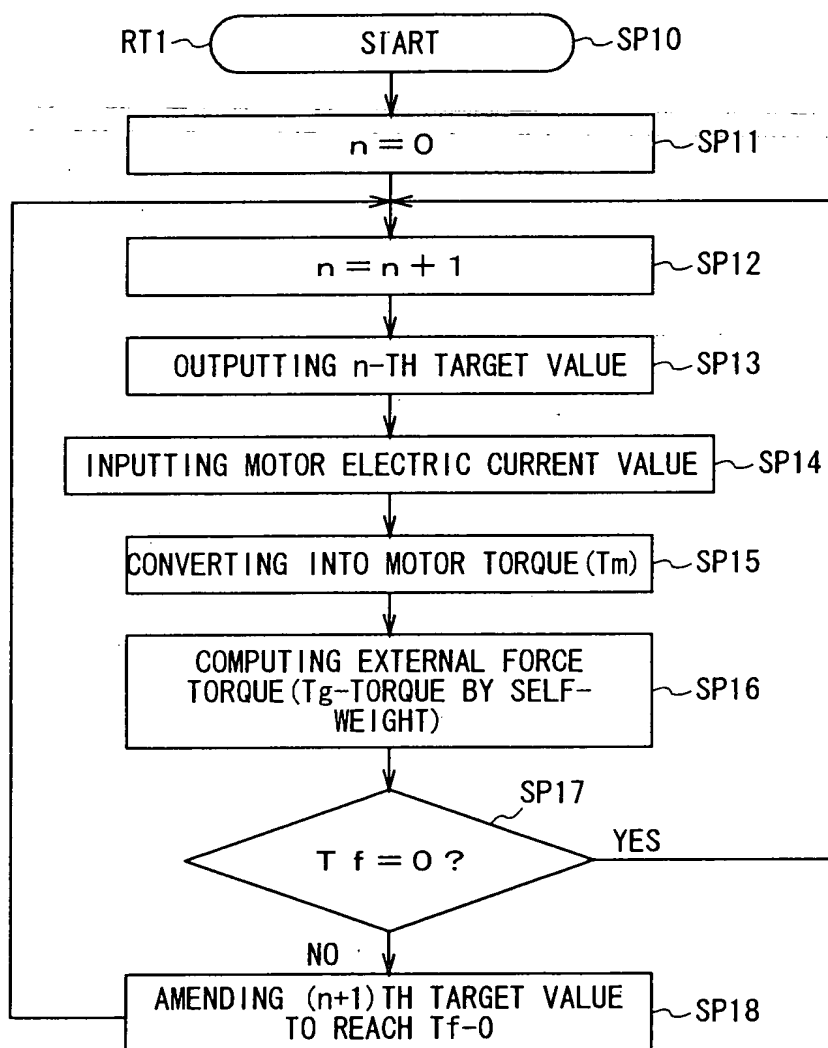


FIG. 22

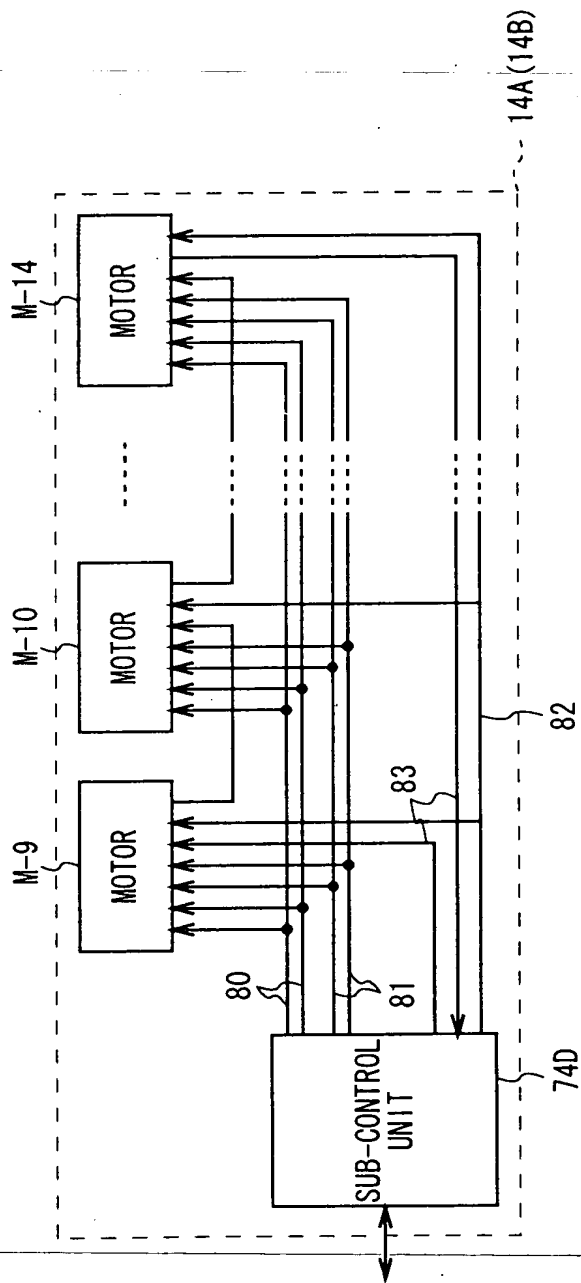


FIG. 23

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Explanation of Reference Numerals

10...robot, 11...belly unit, 12...head unit, 13A, 13B...arm units,
14A, 14B...leg units, 43...ankle joint mechanism, 44...foot unit,
70...main control unit, 73A through 73D...sub-control units,
106...output axis, 111...control substrate, 112...power substrate,
148...CPU, M-1 through M-14...motors, and RT1...unleveled ground
walking controlling procedure.

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